

A lane recognition apparatus for a vehicle is comprised of a camera and a processor. The camera is installed to the vehicle and picks up a road image ahead of the vehicle. The processor is coupled to the camera. The processor is arranged to detect a plurality of lane marker candidate points from the road image, to calculate a road model parameter representative of a road shape ahead of the vehicle on the basis of the lane marker candidate points, to calculate a deviation between the lane marker candidate point and an estimated candidate point estimated from the road model parameter, and to determine whether the road image is employed for detecting the lane marker, on the basis of the deviation.

**SECRET**